

In the Claims:

Please amend the claims as follows:

1. (currently amended) A robot wrist for an industrial robot, said robot wrist (8) comprising a wrist housing (9) and a wrist part (5), here designated tilt, journalled at the wrist housing (9), wherein the tilt (5) is rotatable relative to the wrist housing (9) about an axis of rotation (55) and comprises a drive unit (14) comprising a motor (16) with a motor housing (18), ~~characterized in that~~ wherein a shell part (20) of the motor housing is designed to connect the tilt (5) to the wrist housing (9).

2. (currently amended) A The robot wrist according to claim 1, ~~characterized in that~~ wherein the tilt comprises a first part (6a) that is rotatable relative to the wrist housing (9) about a first axis of rotation (55), and a second part (6b) that is connected to the first part (6a) and designed to support a toolholder (7) or the like and that is rotatable relative to the first part (6a) about a second axis of rotation (56).

3. (currently amended) A The robot wrist according to claim 2, ~~characterized in that~~ wherein the drive unit (14) is arranged for rotation of the second part (6b) relative to the first part (6a) about the second axis of rotation (56).

4. (currently amended) A The robot wrist according to claim 1, wherein 1 or 2, ~~characterized in that~~ the drive unit (14) is arranged for rotation of the tilt (5) relative to the wrist

housing (9).

5. (currently amended) A The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the outside of the shell part is designed to connect the tilt (5) to the wrist housing (9).

6. (currently amended) A The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the motor (16) comprises a stator (22) and a rotor (21) arranged in the motor housing (18), the shell part (20) being adapted to surround the stator (22).

7. (currently amended) A The robot wrist according to claim 6, ~~characterized in that~~ wherein the stator (22) makes contact with the shell part (20).

8. (currently amended) A The robot wrist according to claim 7, ~~characterized in that~~ wherein the stator (22) makes contact with the inside of the shell part.

9. (currently amended) A The robot wrist according to claim 8, ~~characterized in that~~ wherein the inside of the shell part comprises a shoulder (24), wherein the stator (22) makes contact with the shoulder (24) to prevent displacement of the stator (22) in an axial direction relative to the motor housing (18).

10. (currently amended) A The robot wrist according to claim 6, wherein ~~any of claims 6-9, characterized in that~~ the motor housing (18) comprises an opening (23) adapted to allow

insertion of the stator (22) into the motor housing, wherein the motor housing (18) comprises a sealing member (26) adapted to seal the opening (23).

11. (currently amended) A The robot wrist according to claim 10, ~~characterized in that~~ wherein the sealing member (26) comprises a front portion (28) adapted to be received inside the shell part (20).

12. (currently amended) A The robot wrist according to claim 9, wherein ~~claims 11 and 9, characterized in that~~ the stator (22) is clamped between the front portion (28) of the sealing member and the shoulder (24) of the shell part.

13. (currently amended) A The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the shell part (20) is provided on its outside with at least one fixing member (30a, 30b), which is rigidly connected to a corresponding fixing member (12a, 12b) in the wrist housing (9).

14. (currently amended) A The robot wrist according to claim 13, ~~characterized in that~~ wherein the fixing member (30a, 30b) of the shell part comprises a recess (33) and ~~that~~ wherein the fixing member (12a, 12b) of the wrist housing comprises a shaft journal (13) received in said recess, or vice versa.

15. (currently amended) A The robot wrist according to claim 13, wherein ~~13 or 14, characterized in that~~ a fixing member (30A, 30B) of the shell part and a corresponding fixing

member (12a, 12b) of the wrist housing (9) make contact with each other via mutual contact surfaces (15, 35), whereby these contact surfaces (15, 35) are provided with countersunk and/or raised portions adapted to engage with each other to transmit a rotary force between the fixing members.

16. (currently amended) A The robot wrist according to claim 13, wherein ~~any of claims 13-15, characterized in that~~ the shell part (20) is provided with two fixing members (30A, 30B) on essentially opposite sides of the shell part.

17. (currently amended) A The robot wrist according to claim 1, wherein ~~any of the preceding claims, characterized in that~~ the robot wrist (8) is designed for a maximum handling weight of at least 100 kg.

18. (currently amended) An industrial robot, ~~characterized in that~~ wherein the industrial robot comprises a robot wrist (8) according to ~~any of claims 1-17~~ claim 1.

19. (currently amended) A tilt intended to be journalled in a wrist housing of a robot wrist for an industrial robot, wherein the tilt (5) is rotatable relative to the wrist housing about an axis of rotation (55) and comprises a drive unit (14) comprising a motor (16) with a motor housing (18), ~~characterized in that~~ wherein a shell part (20) of the motor housing (18) is designed to connect the tilt (5) to the wrist housing.

20. (currently amended) A The tilt according to claim 19, ~~characterized in that~~ wherein

the tilt (5) comprises a first part (6a) that is rotatable relative to the wrist housing about a first axis of rotation, and a second part (6b) that is connected to the first part (6a) and is designed to support a toolholder (7) or the like and that is rotatable relative to the first part (6a) about a second axis of rotation (56).

21. (currently amended) A The tilt according to claim 20, characterized in that wherein the drive unit (14) is adapted for rotation of the second part (6b) relative to the first part (6a) about the second axis of rotation (56).

22. (currently amended) A The tilt according to claim 19, wherein 19 or 20, ~~characterized in that~~ the drive unit (14) is adapted for rotation of the tilt (5) relative to the wrist housing.